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Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

Claims 1-34 (cancelled)

1   Claim 35 (new): A relative location data correction

2   apparatus for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said apparatus comprising:

6   a first shape data obtaining unit for obtaining first

7   shape data from a first map database;

8   a relative location data creating unit for creating

9   relative location data of an event occurrence point,

10   wherein said relative location data indicates relative

11   location to a node designated in said first shape data;

12   a second shape data obtaining unit for obtaining

13   second shape data from a second map database, wherein said

14   second shape data has a second point corresponding to said

15   event occurrence point;

16   a first determining unit for determining a first total

17   length of the first shape data; and

18   a second determining unit for a second total length of

19   the second shape data; and

20   a correction unit for correcting said relative

21   location data by using said first total length and said

22   second total length.

1   Claim 36 (new): The relative location data correction

2   apparatus according to claim 35,

3   wherein said correction unit corrects the relative

4   location data by using a ratio of said first total length

5   to said second total length.

1   Claim 37 (new): A rrelative location data correction

2   apparatus for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said apparatus comprising:

6   a transmission apparatus including:

7   a first map database;

8   location   expression   conversion   means   for

9   converting an event occurrence point into relative location

10   data to a node designated in a first shape data, said first

11   shape data is obtained from said first map database and

12   represents the periphery of said event occurrence point;

13   and

14   first   total   length   determination   means   for

15   determining a first total length of said first shape data;

16   wherein said transmission apparatus transmits said

17   relative location data, and first shape data, and said

18   first total length, and

19   a reception apparatus including:

20   a second map database;

21   second total length determination means for

22   determining a total length of a second shape data, which is

23   obtained from said second map database and to which a

24   second point corresponding to said event occurrence point

25   belongs;

26   first relative location correction means for

27   correcting said relative location data by using said first

28   total length and said second total length; and

29   event occurrence point specification means for

30   specifying location of said second point corresponding to

31   said event occurrence point, based on said corrected

32   relative location and said second shape data.

1   Claim 38 (new): A relative location data correction

2   apparatus for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said apparatus comprising:

6   a transmission apparatus including:

7   a first map database; and

8   location expression conversion means for

9   converting an event occurrence point into relative location

10   data to a node designated in a first shape data, based on

11   the first shape data obtained from said first map database

12   and representing the periphery of said event occurrence

13   point,

14   wherein said transmission apparatus transmits said

15   relative location data and said first shape data, and

16   a reception apparatus;

17   first total length determination means for

18   determining a first total length of said first shape data

19   transmitted by said transmission apparatus;

20   a second map database;

21   second total length determination means for

22   determining a second total length of a second shape data

23   which is obtained from said second map database and to

24   which a second point corresponding to said event occurrence

25   point belongs;

26   first relative location correction means for

27   corrects said relative location data by using said first

28   total length and said second total length; and

29   event occurrence point specification means for

30   specifying said second point corresponding to said event

31   occurrence point, based on said corrected relative location

32   data and said second shape data.

1   Claim 39 (new): The relative location data correction

2   apparatus according to claim 37,

3   wherein said transmission apparatus further includes:

4   shape data compression/transformation means for

5   creating a first processed shape data by an irreversible

6   compression process said first shape data, or a shape

7   transformation process of said first shape data;

8   first shape data decoding means for creating a

9   third shape data by decoding said first processed shape

10   data;

11   third total length determination means for

12   determining a third total length of said third shape data;

13   and

14   second relative location correction means for

15   creating a second corrected relative location data by

16   correcting said relative location data by using said first

17   total length and said third total length,

18   wherein said transmission apparatus transmits said

19   second corrected relative location data, said first

20   processed shape data, and said third total length, and

21   wherein said reception apparatus further includes:

22   second shape data decoding means for decoding

23   said first processed shape data,

24   wherein said first relative location correction

25   means corrects said second corrected relative location data

26   by using said third total length and said second total

27   length.

1   Claim 40 (new): The relative location data correction

2   apparatus according to claim 38,

3   wherein said transmission apparatus further includes:

4   shape data compression/transformation means for

5   creating a first processed shape data by performing an

6   irreversible compression process of said first shape data,

7   or a shape transformation process of said first shape data;

8   first shape data decoding means for creating a

9   third shape data by decoding said first processed shape

10   data;

11   third total length determination means for

12   determining a third total length of said third shape data;

13   and

14   second relative location correction means for

15   creating a second relative location data by correcting said

16   relative location data by using said first total length and

17   said third total length,

18   wherein said transmission apparatus transmits said

19   second corrected relative location data and said first

20   processed shape data, and

21   wherein said reception apparatus further includes:

22   second shape data decoding means for creating a

23   fourth shape data by decoding said first processed shape

24   data; and

25   fourth total length determination means for

26   determining a fourth total length of said fourth shape

27   data,

28   wherein said first relative location correction

29   means corrects said second corrected relative location data

30   by using said second total length and said fourth total

31   length determined by said third total length determination

32   (means and.

1   Claim 41 (new): The relative location data correction

2   apparatus according to one of claims 37 to 40,

3   wherein said first shape data has a first feature node

4   designated between nodes at both terminal ends of said

5   first shape data,

6   wherein said second shape data has a second feature

7   node corresponding to said first feature node, and

8   wherein said location expression conversion means

9   converts said event occurrence point into a relative

10   location data to said feature node.

1   Claim 42 (new): The relative location data correction

2   apparatus according to claim 39,

3   wherein said first shape data has at least tow first

4   feature nodes designated between nodes at both terminal

5   ends of said first shape data,

6   wherein said second shape data has second feature

7   nodes corresponding to said first feature nodes,

8   wherein said third shape data has third feature nodes

9   corresponding to said first feature nodes,

10   if said event occurrence point is located between said

11   first feature nodes and said second point is between said

12   second feature nodes, wherein said first total length

13   determination means calculates a total length of a distance

14   between said first feature nodes, said second total length

15   determination means calculates a total length of a distance

16   between said second feature nodes, and said third total

17   length determination means calculates a total length of a

18   distance between said third feature nodes.

1   Claim 43 (new): The relative location data correction

2   apparatus according to claim 40,

3   wherein said first shape data has at least tow first

4   feature nodes designated between nodes at both terminal

5   ends of said first shape data,

6   wherein said second shape data has second feature

7   nodes corresponding to said first feature nodes,

8   wherein said third shape data has third feature nodes

9   corresponding to said first feature nodes,

10   wherein said fourth shape data has fourth feature

11   nodes corresponding to said first feature nodes, and

12   if said event occurrence point is located between said

13   first feature nodes, wherein said first total length

14   determination means calculates a total length of a distance

15   between said first feature nodes, said second total length

16   determination means calculates a total length of a distance

17   between said second feature nodes, said third total length

18   determination means calculates a total length of a distance

19   between said third feature nodes, and said fourth total

20   length determination means calculates a total length of a

21   distance between said fourth feature nodes.

1   Claim 44 (new): The relative location data correction

2   apparatus according to one of claims 37 to 43,

3   wherein said each total length is determined with

4   calculation or with reference to a predetermined value.

1   Claim 45 (new): The relative location data correction

2   apparatus according to one of claims 41 to 44,

3   wherein said transmission apparatus further transmits

4   shape data attribute information for identifying said each

5   first feature node and indicating type of said each first

6   feature node.

1   Claim 46 (new): The relative location data correction

2   apparatus according to one of claims 41 to 45,

3   wherein said each first feature node is designated at

4   a point whereat an angle difference in a predetermined area

5   for a link constituting said first shape data is equal to

6   or greater than a predetermined angle.

1   Claim 47 (new): A relative location data correction

2   method, for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said method comprising the steps

6   of:

7   obtaining a first shape data from a first map

8   database;

9   creating a relative location data of an event

10   occurrence point to a node in said first shape data;

11   determining a first total length of said first shape

12   data;

13   obtaining a second shape data corresponding to said

14   first shape data from a second map database;

15   determining a second total length of said second shape

16   data; and

17   correcting said relative location data by using said

18   first total length and said second total length.

1   Claim 48 (new): The relative location data correction

2   method according to claim 47,

3   wherein, in the step of correcting said relative

4   location data, said relative location data is corrected by

5   using a ratio of said first total length to said second

6   total length.

1   Claim 49 (new): A relative location data correction

2   method, for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said method comprising the steps

6   of:

7   obtaining a first shape data including an event

8   occurrence point from a first map database;

9   converting a location expression of said event

10   occurrence point into a relative location data to a node in

11   the said first shape data;

12   determining a first total length of said first shape

13   data;

14   transmitting relative location data for transmitting

15   said relative location data, said first shape data, and

16   said first total length;

17   obtaining a second shape data including a second point

18   corresponding to said event occurrence point form a second

19   map database;

20   determining a second total length of said second shape

21   data; and

22   first correcting for correcting said relative location

23   data by using said first total length and said second total

24   length.

1   Claim 50 (new): A relative location data correction

2   method, for correcting a shift of a location of a

3   predetermined point, said location is relatively indicated

4   as relative location data and said shift is a different

5   between two map databases, said method comprising the steps

6   of:

7   obtaining a first shape data including an event

8   occurrence point from a first map database;

9   converting a location expression of said event

10   occurrence point into a relative location data to a node in

11   the said first shape data;

12   transmitting for transmitting said relative location

13   data and said first shape data;

14   determining a first total length of said first shape

15   data;

16   obtaining a second shape data including a second point

17   corresponding to said event occurrence point form a second

18   map database;

19   determining a second total length of said second shape

20   data; and

21   first correcting for correcting said relative location

22   data by using said first total length and said second total

23   length.

1   Claim 51 (new): The relative location data correction

2   method according to claim 49, further comprising the steps

3   of:

4   compressing/transforming   for   creating   a   first

5   processed shape data by performing an irreversible

6   compression process said first shape data, or a shape

7   transformation process of said first shape data;

8   a first decoding for creating a third shape data by

9   decoding said first processed shape data;

10   a determining a third total length of said third shape

11   data;

12   a second correcting for creating a second corrected

13   relative location data by correcting said relative location

14   data by using said first total length and said third total

15   length; and

16   a second decoding for decoding a processed first shape

17   data,

18   wherein, in the step of transmitting, said second

19   corrected relative location data, said first processed

20   shape data, and said third total length are transmitted,

21   and

22   wherein, in the step of first correcting, said

23   relative location data is corrected by correcting said

24   second corrected relative location data by using said third

25   total length and said second total length.

1   Claim 52 (new): The relative location data correction

2   method according to claim 50, further comprising the steps

3   of:

4   compressing/transforming   for   creating   a   first

5   processed shape data by performing an irreversible

6   compression process of said first shape data, or a shape

7   transformation process of said first shape data;

8   a first decoding for creating a third shape data by

9   decoding said first processed shape data;

10   a determining a third total length of said third shape

11   data;

12   a second correcting for creating a second corrected

13   relative location data by using said first total length and

14   said third total length;

15   a second decoding for creating a fourth shape data of

16   decoding said first processed shape data; and

17   a determining a fourth total length of said fourth

18   shape data,

19   wherein, in the step of transmitting, said second

20   corrected relative location data and said first processed

21   shape data is transmitted, and

22   wherein, in the step of first correcting, said

23   relative location data is corrected by correcting said

24   second corrected relative location data by using said

25   second total length and said fourth total length.

1   Claim 53 (new): The relative location data correction

2   method according to one of claims 49 to 52,

3   wherein said first shape data has a first feature node

4   designated between nodes at both terminal ends of said

5   first shape data,

6   wherein said second shape data has a second feature

7   node corresponding to said first feature node, and

8   wherein said location expression conversion means

9   converts said event occurrence point into a relative

10   location data to said feature node.

1   Claim 54 (new): The relative location data correction

2   method according to claim 51,

3   wherein said first shape data has at least tow first

4   feature nodes designated between nodes at both terminal

5   ends of said first shape data,

6   wherein said second shape data has second feature

7   nodes corresponding to said first feature nodes,

8   wherein said third shape data has third feature nodes

9   corresponding to said first feature nodes, and

10   if said event occurrence point is located between said

11   first feature nodes and said second point is between said

12   second feature nodes, wherein a total length of a distance

13   between said first feature nodes is determined as said

14   first total length, a total length of a distance between

15   said second feature nodes is determined as said second

16   total length, and a total length of a distance between said

17   third feature nodes is determined as said third total

18   length.

1   Claim 55 (new): The relative location data correction

2   method according to claim 52,

3   wherein said first shape data has at least tow first

4   feature nodes designated between nodes at both terminal

5   ends of said first shape data,

6   wherein said second shape data has second feature

7   nodes corresponding to said first feature nodes,

8   wherein said third shape data has third feature nodes

9   corresponding to said first feature nodes,

10   wherein said fourth shape data has fourth feature

11   nodes corresponding to said first feature nodes, and

12   if said event occurrence point is located between said

13   first feature nodes and said second point is between said

14   second feature nodes, wherein a total length of a distance

15   between said first feature nodes is determined as said

16   first total length, a total length of a distance between

17   said second feature nodes is determined as said second

18   total length, a total length of a distance between said

19   third feature nodes is determined as said third total

20   length, and a total length of a distance between said

21   fourth feature nodes is determined as said fourth total

22   length.

1   Claim 56 (new): The relative location data correction

2   method according to one of claims 49 to 55,

3   wherein said each total length is determined with

4   calculation or with reference to a predetermined value.

1   Claim 57 (new): The relative location data correction

2   method according to one of claims 53 to 56,

3   wherein, in the step of transmitting, shape data

4   attribute information for identifying said each first

5   feature node and indicating type of said each first feature

6   node are transmitted.

1   Claim 58 (new): The relative location data correction

2   method according to one of claims 53 to 57,

3   wherein said each first feature node is designated at

4   a point whereat an angle difference in a predetermined area

5   for a link constituting said first shape data is equal to

6   or greater than a predetermined angle.

1   Claim 59 (new): A relative location data correction

2   program, which permits a computer to perform a relative

3   location data correction method according to one of claims

4   47 to 58.

1   Claim 60 (new): A shape data generation apparatus for

2   generating a shape data representing a predetermined

3   section including an event occurrence point, said apparatus

4   comprising:

5   a map database;

6   a map data obtaining unit for obtaining a map data

7   covering an area where said event occurrence point exists;

8   a shape data obtaining unit for obtaining a shape data

9   from said map data, wherein said shape data includes said

10   event occurrence point;

11   a relative location data creating unit for converting

12   a location expression of said event occurrence point into

13   a relative location to a node in said shape data;

14   a feature node designating unit for designating a

15   feature node which is a point in said predetermined section

16   or in the periphery of said section and satisfies a

17   predetermined condition; and

18   a shape data updating unit for updating said shape

19   data so as to have said feature node, if said feature node

20   is designated in the periphery of said section.

1   Claim 61 (new): The shape data generation apparatus

2   according to claim 60, further comprising:

3   a nearest feature node obtaining unit for obtaining a

4   feature node nearest to said event occurrence point; and

5   a location expression converting unit for converting

6   said relative location data into a relative location to

7   said nearest feature node.

1   Claim 62 (new): The shape data generation apparatus

2   according to claim 60 or 61,

3   wherein, if a start point or an end point of said

4   shape data is not suitable for the predetermined condition,

5   said feature node determining unit checks whether a more

6   suitable point than said start point or said end point

7   exists in said shape data, and then determines said feature

8   node in the vicinity of said start point or said end point.

1   Claim 63 (new): The shape data generation apparatus

2   according to one of claims 60 to 62,

3   wherein said feature node designating unit designates

4   plural feature nodes by selecting a point which is located

5   within a predetermined distance from a previously selected

6   point as a feature node and satisfies said predetermined

7   condition, and repeating said selecting point along said

8   shape data predetermined number of times.

1   Claim 64 (new): The shape data generation apparatus

2   according to one of claims 60 to 63,

3   wherein said predetermined condition is that an

4   absolute declination value at a point in a predetermined

5   area between two continuous links characterized in that

6   said point that satisfies said predetermined condition is

7   a point for which an absolute declination value is equal to

8   or greater than a predetermined value.

1   Claim 65 (new): A shape data generation method, for

2   obtaining map data from a map database and for generating

3   a shape data representing a predetermined section, said

4   method comprising the step of:

5   obtaining a map data covering an area where said event

6   occurrence point exists;

7   obtaining a shape data from said map data, wherein

8   said shape data includes said event occurrence point;

9   creating a relative location data by converting a

10   location expression of said event occurrence point into a

11   relative location to a node in said shape data;

12   designating a feature node which is a point in said

13   predetermined section or in the periphery of said section

14   and satisfies a predetermined condition; and

15   updating said shape data so as to have said feature

16   node, if said feature node is designated in the periphery

17   of said section.

1   Claim 66 (new):   The shape data generation method

2   according to claim 65, further comprising:

3   obtaining a feature node nearest to said event

4   occurrence point; and

5   converting said relative location data into a relative

6   location to said nearest feature node.

1   Claim 67 (new):   The shape data generation method

2   according to claim 65 or 66,

3   wherein, if a start point or an end point of said

4   shape data is not suitable for the predetermined condition,

5   in the step of determining feature node, checking whether

6   a more suitable point than said start point or said end

7   point exists in said shape data, and then determining said

8   feature node in the vicinity of said start point or said

9   end point.

1   Claim 68 (new): The shape data generation method

2   according to one of claims 65 to 67,

3   wherein, in the step of designating feature node,

4   plural feature nodes are designated by selecting a point

5   which is located within a predetermined distance from a

6   previously selected point as a feature node and satisfies

7   said predetermined condition, and repeating said selecting

8   point along said shape data predetermined number of times.

1   Claim 69 (new): The shape data generation method

2   according to one of claims 65 to 67,

3   wherein said predetermined condition is that an

4   absolute declination value at a point in a predetermined

5   area between two continuous links characterized in that

6   said point that satisfies said predetermined condition is

7   a point for which an absolute declination value is equal to

8   or greater than a predetermined value.

1   Claim 70 (new):   A shape data generation program,

2   which permits a computer to perform a shape data generation

3   method according to one of claims 65 to 69.